

8. (Amended) Device according to claim 6, wherein the target comprises a groove with substantially vertical walls.

9. (Amended) Device according to claim 6, wherein the target comprises an elevation with substantially vertical sides.

Cancel claim 10.

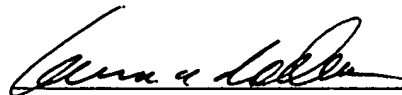
REMARKS

Claims 1 to 9 have been amended to more closely conform the application to U.S. standards. Claim 10 has been cancelled. No new matter has been introduced, and all multiple dependent claims have been cancelled.

Attached is a marked-up version of the changes made to the claims by the current Preliminary Amendment.

Entry is believed in order.

Respectfully submitted,



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Versions with Markings to Claims to Show Changes

1. (Amended) Method for synchronizing a robot [(1)] that includes a control system [(2)], a first robot part [(3)] and a second robot part [(5)] movably attached to the first robot part [(3)], whereby the position of a target [(4)] arranged on the first robot part [(3)] is determined by the passage of a sensor [(6)] arranged on the second robot [(5)], comprising the steps of causing [characterized in that] the target [(4) is caused] to include several distinct detectable changes [(4a, 4b)] comprising step-like structural changes, sensing [that] at least two of said [these] distinct detectable changes [(4a, 4b) are sensed] by the sensor [(6)], calculating [that] the position [(4c)] of the target [(4) is calculated] and introducing [that] the calculated target position [is introduced] into the control system and comparing the target position [compared] with a calibration position for the target [(4)] in the control system.

2. (Amended) Method according to claim 1, wherein calculating [characterized in that] the position of the target is effected by reading with the [(4) is read with a] sensor [(6) in the form of] which comprises a non-contact sensor.

3. (Amended) Method according to claim 1, wherein calculating [characterized in that] the position of the target is effected by reading with the [(4) is read with a] sensor [in the form of] which comprises a contact sensor.

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5. (Amended) Method according to claim 1, wherein [characterized in that] the target comprises [(4) is designed as] an elevation with [essentially] substantially vertical sides [(4a') and (4b')].

6. (Amended) Device for synchronizing a robot [(1)] that includes a control system [(2)], a first robot part [(3)] and a second robot part [(5)] movably attached to the first robot part [(3) where], the device [includes] comprising a target [(4)] arranged on the first robot part [(3)] and a sensor [(6)] arranged on the second robot part, wherein [(5) characterized in that] the target [(4)] includes several distinct [by the sensor (6)] detectable changes [(4a, 4b)] comprising step-like structural changes.

7. (Amended) Device according to claim 6, wherein [characterized in that] the step-like structural changes comprise instantaneous level differences in the form of shoulder parts [(7)].

8. (Amended) Device according to claim 6, wherein [characterized in that] the target comprises [(4) is designed as] a groove with [essentially] substantially vertical walls [(4a) and (4b)].

9. (Amended) Device according to claim 6, wherein [characterized in that] the target comprises [(4) is designed as] an elevation with [essentially] substantially vertical sides [(4a) and (4b)].

Cancel claim 10.

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